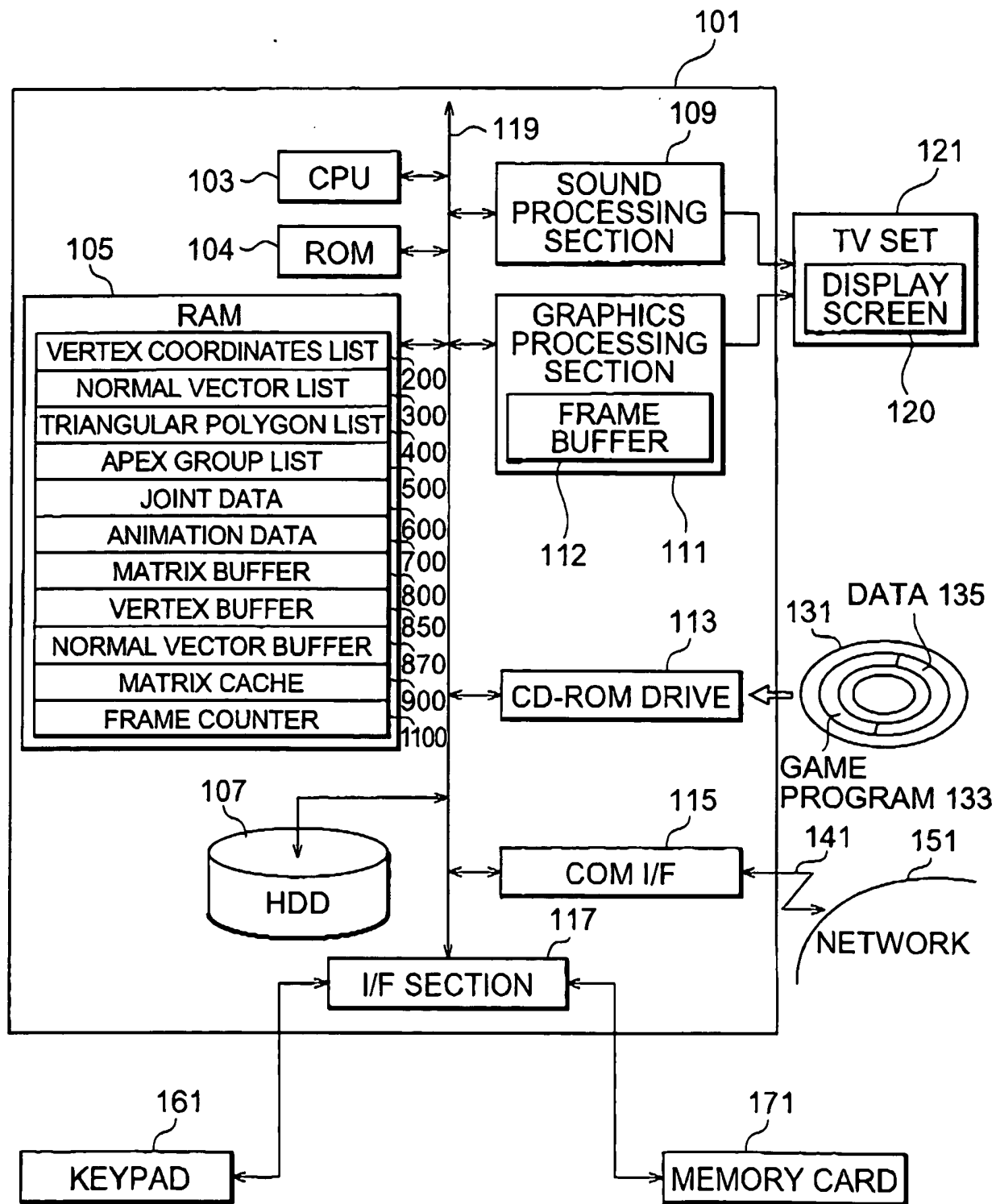


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Fig.1

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Fig.2

210 200 220

INDEX	COORDINATES (x,y,z)
vtx0	(0 , 0 , 0)
vtx1	(0 , 0 , 100)
vtx2	(0 , 100 , 0)
vtx3	(0 , 100 , 100)
vtx4	(100 , 0 , 0)
⋮	⋮

Fig.3

310 300 320

INDEX	NORMAL VECTOR (x,y,z)
nml0	(1 , 0 , 0)
nml1	(- 1 , 0 , 0)
nml2	(0 , 0 , - 1)
nml3	(- 1 , - 1 , 0)
nml4	(0 , - 1 , 0)
⋮	⋮

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Fig.4

400

410 INDEX	420 VERTEX 0	430 VERTEX 1	440 VERTEX 2
plg0	vtx0 / nml0	vtx1 / nml2	vtx2 / nml3
plg1	vtx0 / nml1	vtx2 / nml3	vtx3 / nml4
⋮	⋮	⋮	⋮

Fig.5

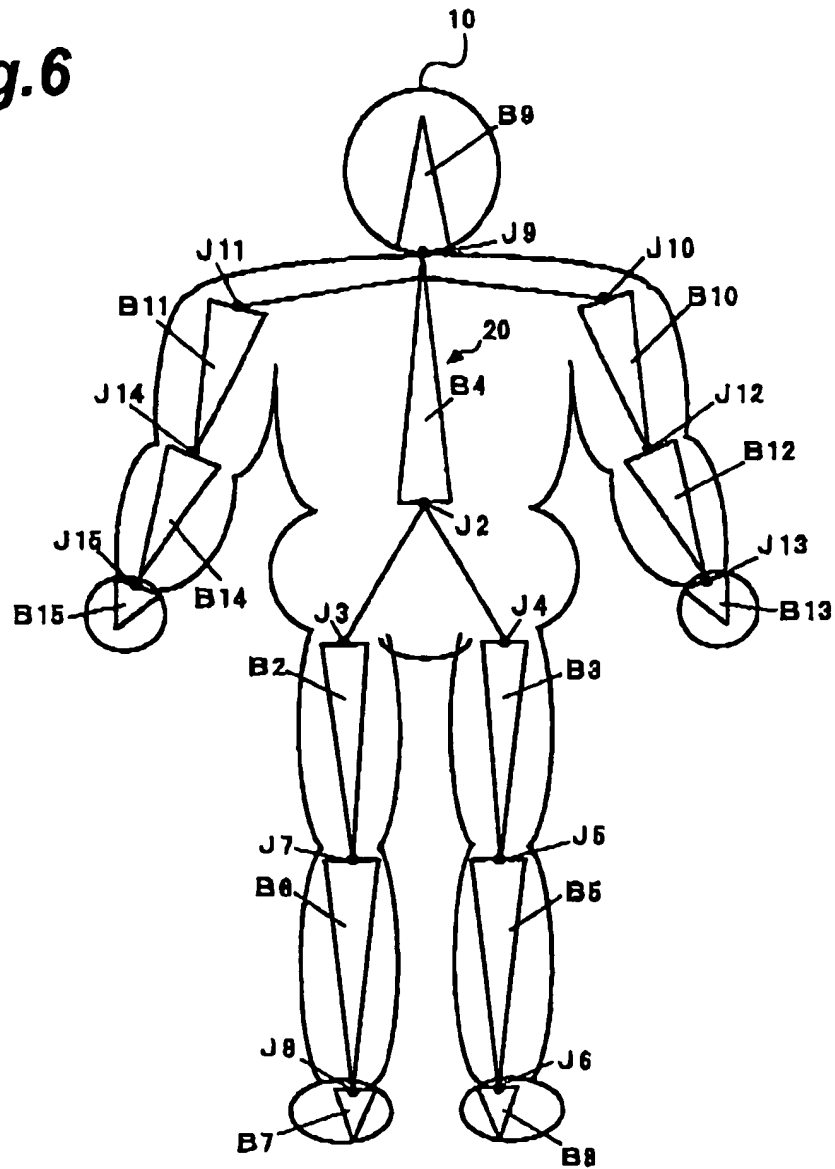
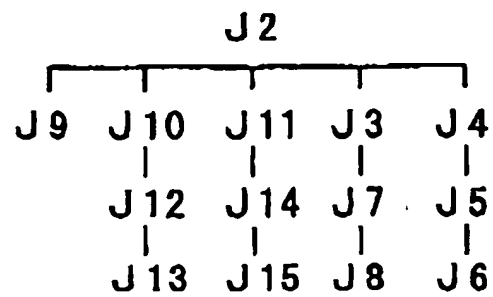
500

VERTEX GROUP LIST

510	NUMBER OF GROUPS		3							VERTEX GROUP 0
520	NUMBER OF MEMBERS		4							
530	VERTEX	vtx1	WEIGHT (540)	1.0	NUMBER OF NORMALS(570)	2	NORMALS (591)	nml0	nml1	
532	VERTEX	vtx2	WEIGHT (542)	1.0	NUMBER OF NORMALS(572)	1	NORMALS (592)	nml10		
534	VERTEX	vtx3	WEIGHT (544)	1.0	NUMBER OF NORMALS(574)	1	NORMALS (593)	nml2		VERTEX GROUP 1
536	VERTEX	vtx4	WEIGHT (546)	1.0	NUMBER OF NORMALS(576)	2	NORMALS (594)	nml3	nml1	
522	NUMBER OF MEMBERS		4							
550	VERTEX	vtx5	WEIGHT (560)	0.5	NUMBER OF NORMALS(580)	1	NORMALS (595)	nml11		
552	VERTEX	vtx6	WEIGHT (562)	0.5	NUMBER OF NORMALS(582)	1	NORMALS (596)	nml4		VERTEX GROUP 2
554	VERTEX	vtx7	WEIGHT (564)	1.0	NUMBER OF NORMALS(584)	1	NORMALS (597)	nml5		
556	VERTEX	vtx8	WEIGHT (566)	1.0	NUMBER OF NORMALS(586)	3	NORMALS (598)	nml6	nml8 nml9	
524	NUMBER OF MEMBERS		1							
558	VERTEX	vtx7	WEIGHT (568)	0.5	NUMBER OF NORMALS(588)	1	NORMALS (599)	nml7		

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Fig.6**Fig.7**

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Fig.8

800

610	Root index	root
612	Basic parallel movement amount (x, y, z)	(0, 0, 0)
614	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 90)
616	Number of joints	4
620	Joint index	Joint0
622	Parent index	root
624	Basic parallel movement amount (x, y, z)	(90, 20, 0)
626	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 135)
628	Number of vertex groups	2
630	Vertex group number	0
632	Vertex group number	2
640	Joint index	Joint1
642	Parent index	Joint0
644	Basic parallel movement amount (x, y, z)	(40, 0, 0)
646	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 45)
648	Number of vertex groups	1
650	Vertex group number	1

Joint 0

Joint 1

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Fig.9A

700	
710	720
Number of joints	Number of frames
2	10

Fig.9B

730		740		700	
Joint index	Rotation angle (Rx, Ry, Rz)				
Joint0	(0, 0, 0)			Frame0	
Joint1	(0, 0, 0)				
Joint0	(10, 0, 135)			Frame1	
Joint1	(-10, 5, 45)				
⋮	⋮				
Joint0	(90, 0, 150)			Frame9	
Joint1	(-90, 45, 45)				

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FIG. 9A

Fig. 10A

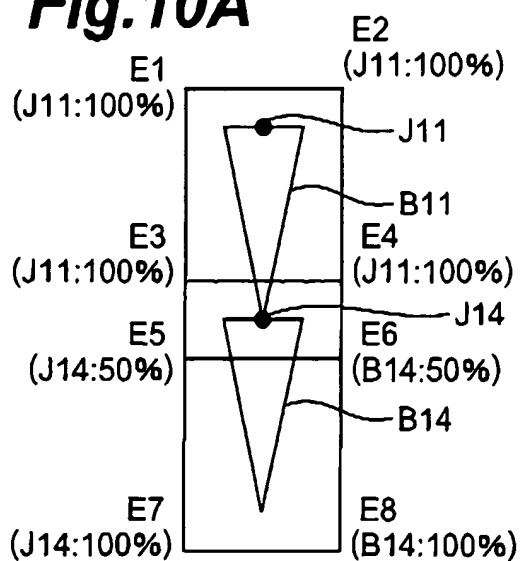


Fig. 10B

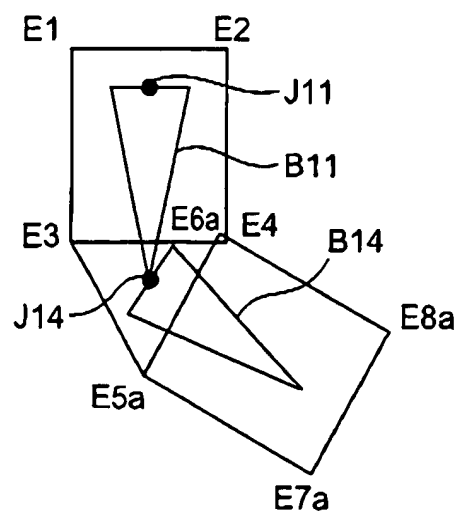


Fig. 10C

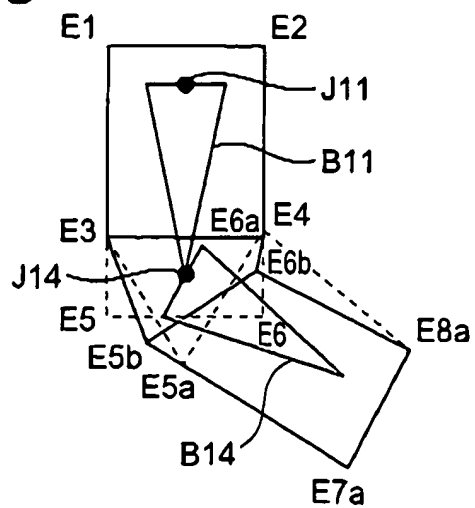
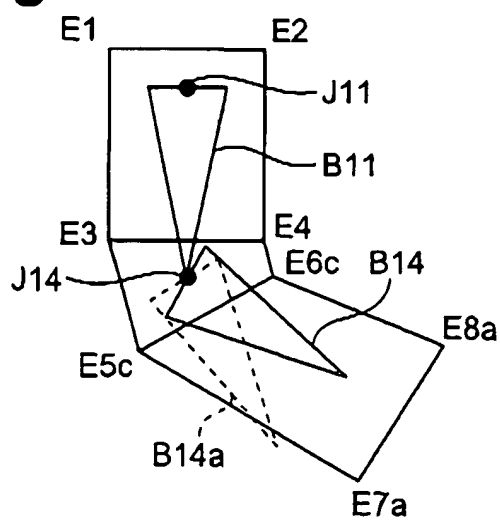
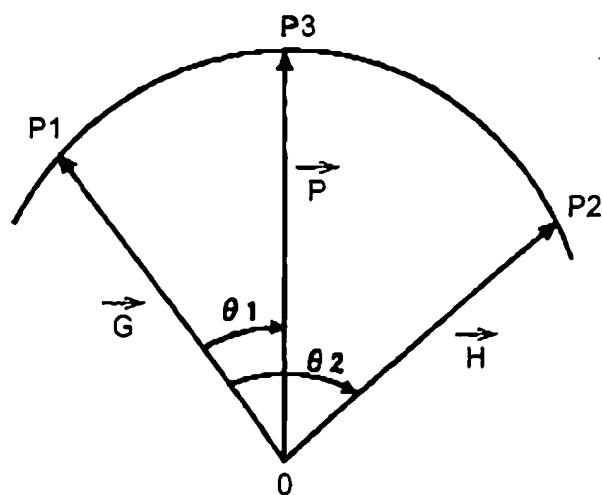


Fig. 10D

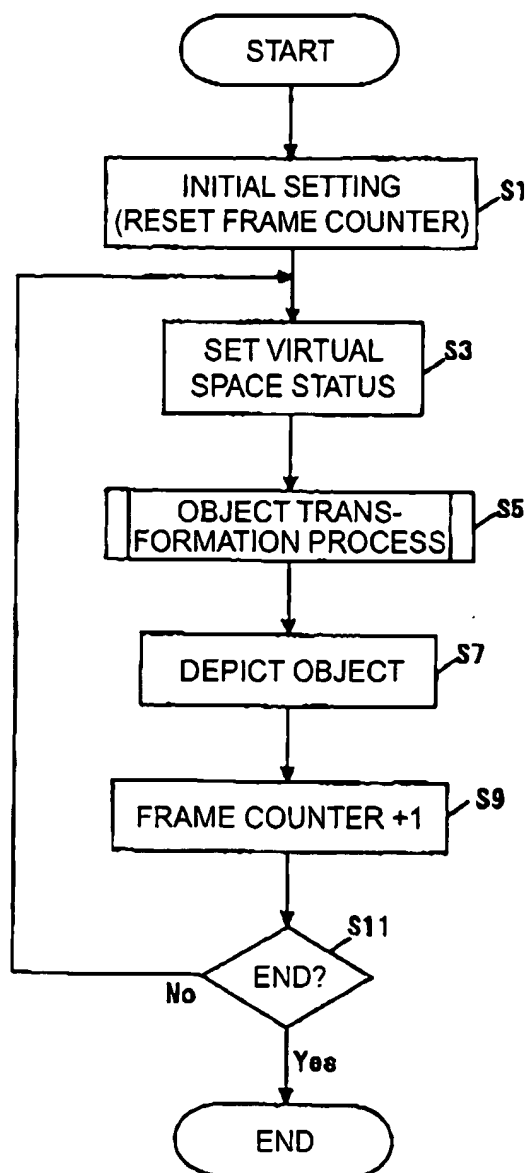


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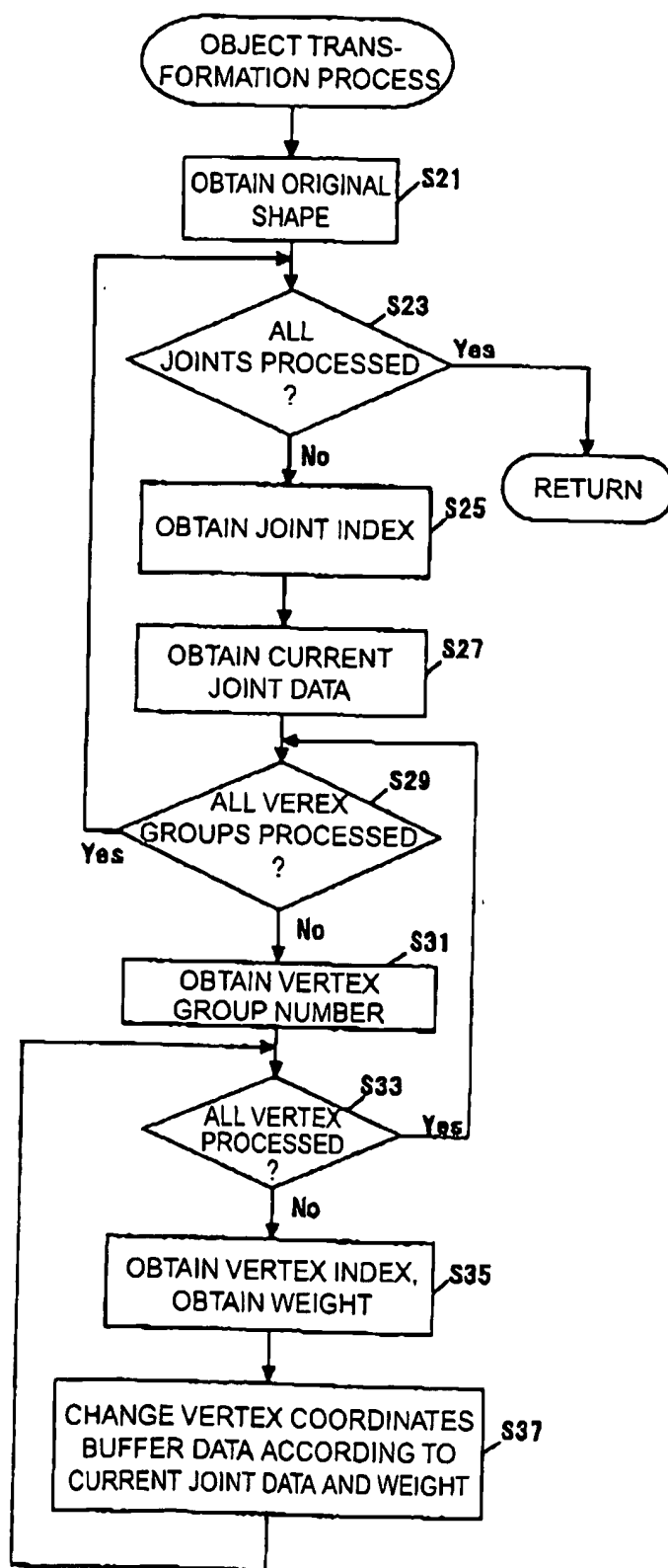
Fig.11

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Fig.13

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Fig.14

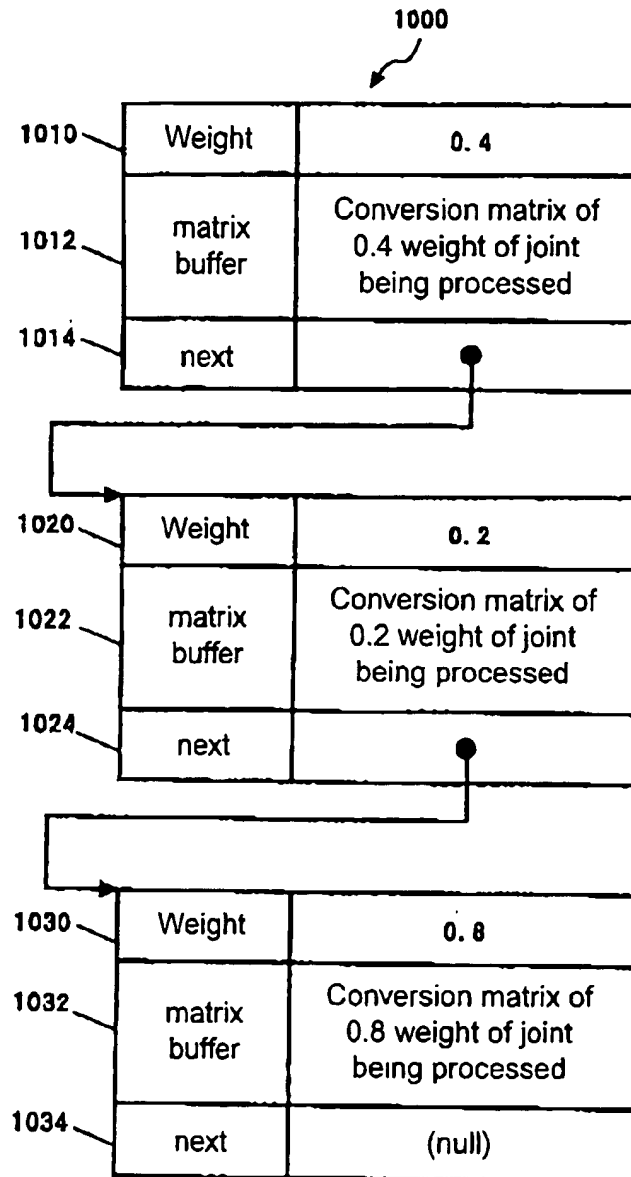
Joint index	Matrix data
root	Root conversion matrix
Joint0	Conversion matrix with 100% weight of joint0
Joint1	Conversion matrix with 100% weight of joint1

Fig.15

Weight	Weight
matrix buffer	Conversion matrix according to weight of joint being processed

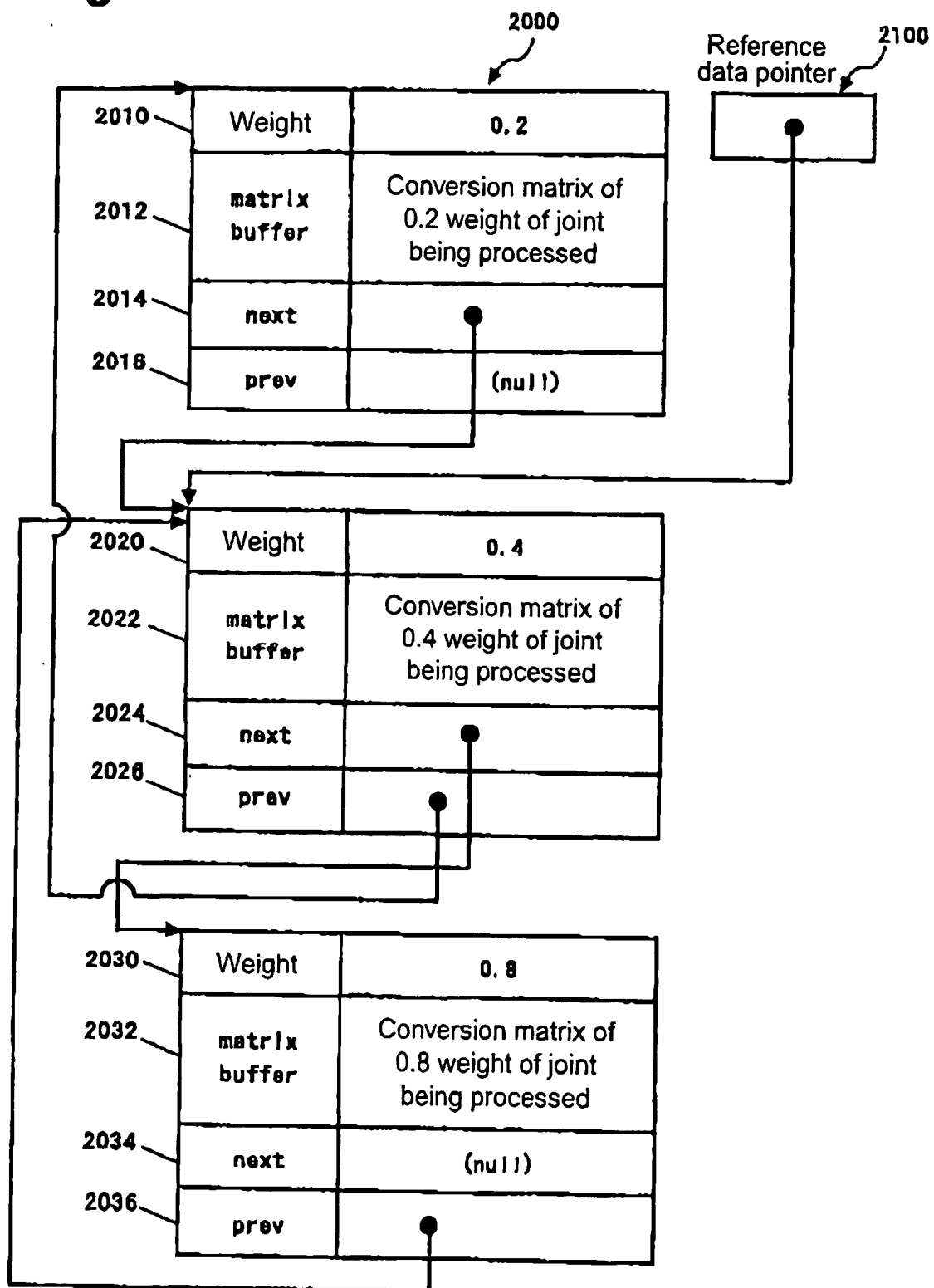
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Fig.16

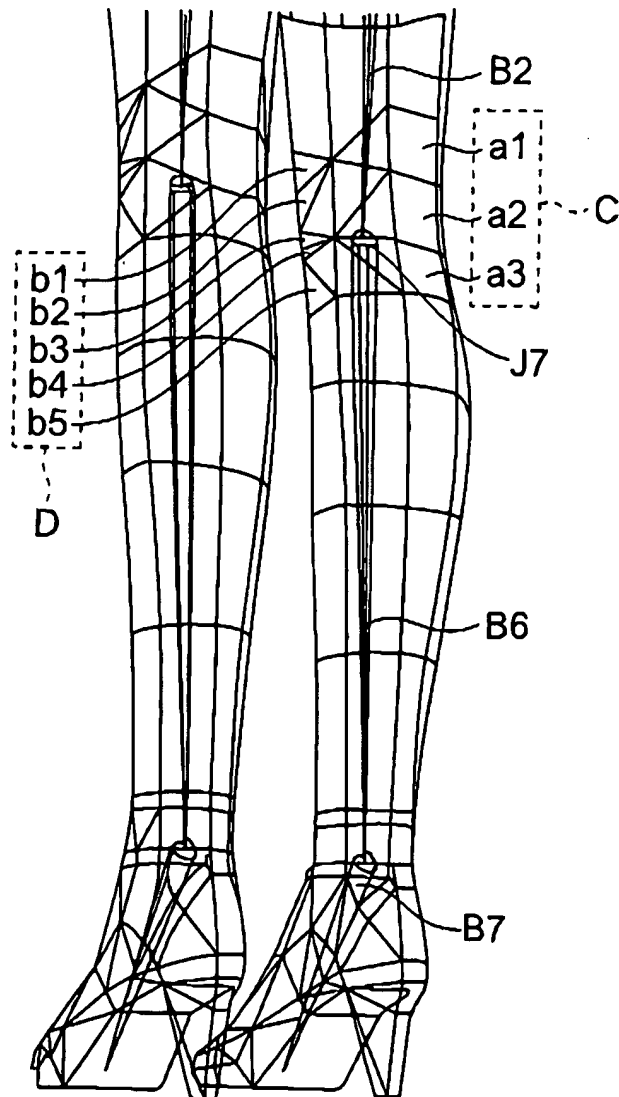
097111-012501

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Fig.17

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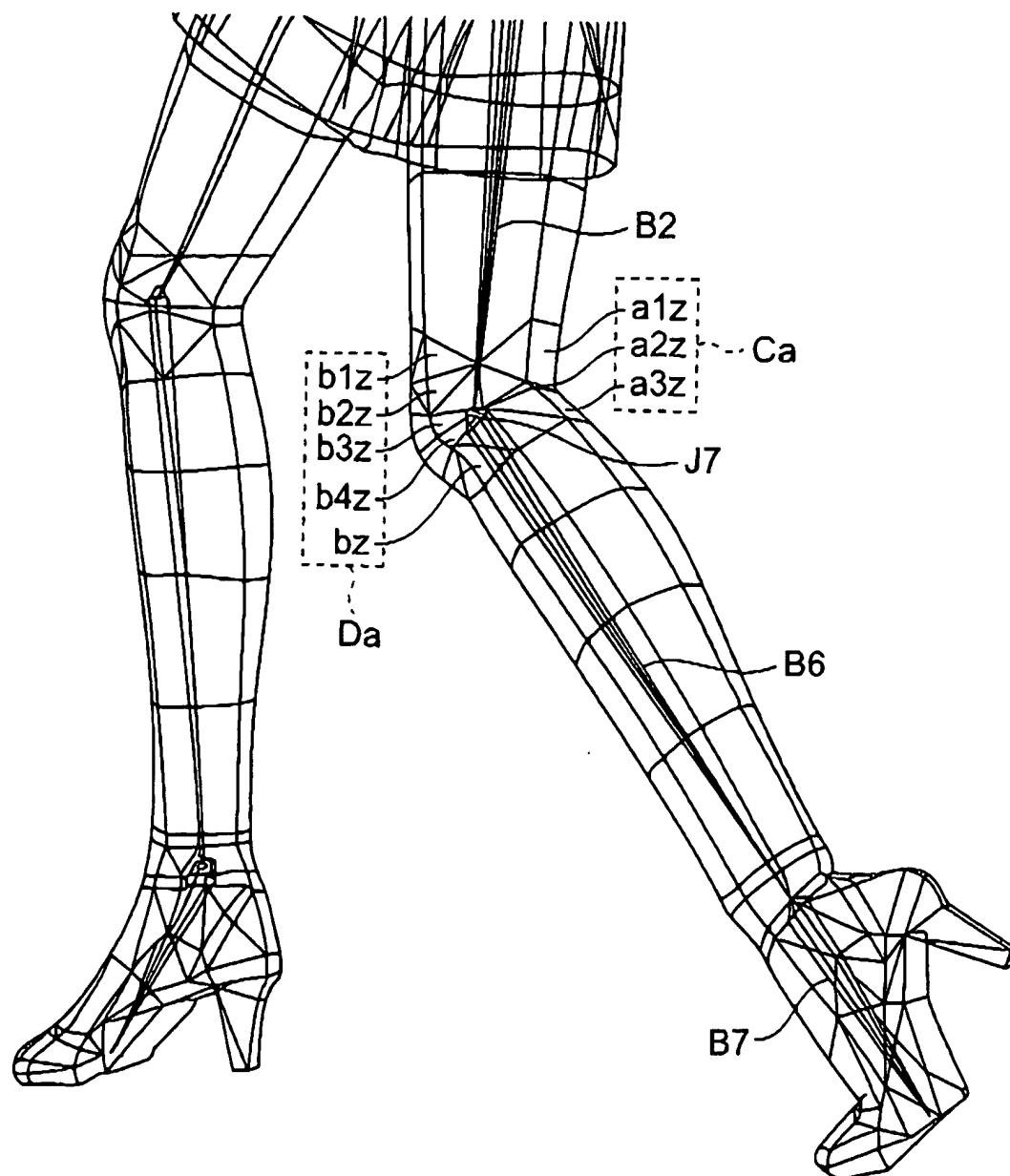
Fig.18



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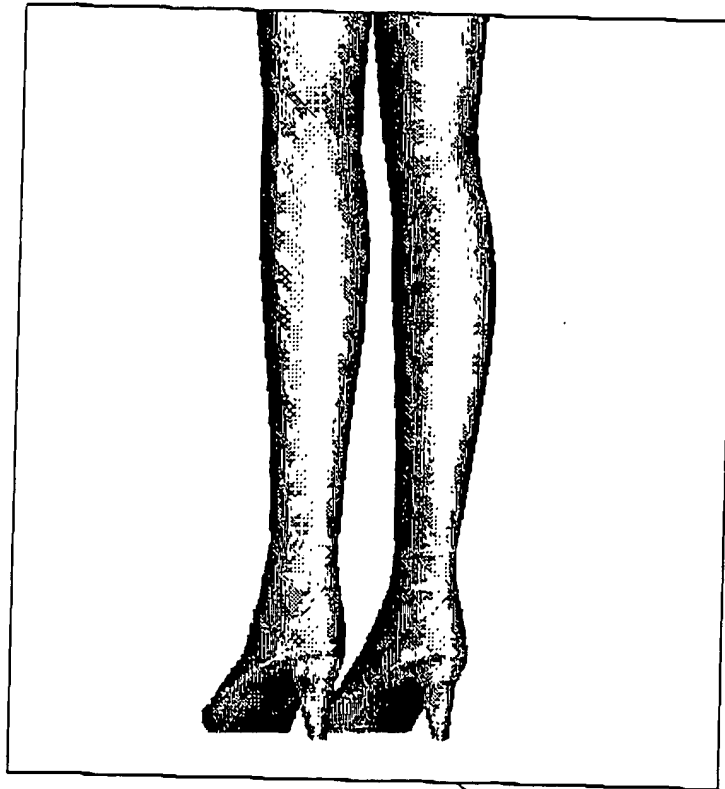
Fig.19



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Fig.20



120

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Fig.21



120

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